

IN THE UNITED STATES PATENT AND TRADEMARK OFFICE

Applicants : Assaf Govari
Serial No. : 09/621,322
Filed : July 20, 2000
Title : MEDICAL SYSTEM CALIBRATION STATIC METAL
COMPENSATION

Art Unit : 3737
Examiner : Eleni M. Mantis Mercader

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November 6, 2009

(Date of Deposit)

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(Name of applicant, assignee, or Registered Representative)

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November 6, 2009

(Date of Signature)

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RESPONSE to Notification of Non-Compliant Appeal Brief

Sir:

In response to the Notification of Non-Compliant Appeal Brief dated October 6, 2009,
Appellant submits Summary of Claimed Subject Matter. A complete Brief is not required, see
M.P.E.P. § 1205.03.

(5) Summary of Claimed Subject Matter

The invention with respect to independent Claim 1 comprises a method for calibrating a medical system (#20) capable of generating a magnetic field (page 12, lines 27-29) for tracking a position of a medical device (page 9, lines 26-29), the method comprising the steps of: defining a mapping volume within the generated magnetic field (page 34 lines 13-22); placing a metallic object within the mapping volume (page 33 lines 27-30); aligning a sensor (#100) at a first point (#210) within the mapping volume and measuring the magnetic field at the first point (#210) with the sensor (#100) to establish a first coordinate position (X_i, Y_i, Z_i) (page 35, lines 8-12); moving the sensor (#100) to a next point ($X_i + dx, Y_i + dy, Z_i + dz$) (#220) along one coordinate axis by an added distance component (dx, dy, dz) and measuring the magnetic field at the next point to establish a next coordinate position (page 35, lines 14-18); interpolating the magnetic field at an intermediate point between the first position (#210) and the next coordinate position (#22) to establish an interpolated intermediate coordinate position (#330a) (page 36, lines 4-13); determining the position difference between the interpolated intermediate coordinate position (#220a) and an actual intermediate coordinate position (page 36, lines 15-19); comparing the position difference to an error limit (page 36, lines 19-22); setting (X_i, Y_i, Z_i) of the next point as ($X_i = X_i + dx, Y_i = Y_i + dy, Z_i = Z_i + dz$) if the position difference is within the error limit and repeating steps (d) – (g) along another coordinate axis (page 36, lines 23-28); and setting the added distance component (dx, dy, dz) by decreasing the value of the added distance component if the position difference is not within the error limit and repeating steps (d) – (g) along the same coordinate axis (page 36 line 30-page 37 line 3).

The invention with respect to independent Claim 11 comprises a method for calibrating a medical system (#20) capable of generating a magnetic field (page 12, lines 27-29) for tracking a position of a medical device (page 9, lines 26-29), the method comprising the steps of: defining a mapping volume within the generated magnetic field (page 34 lines 13-22); placing a metallic object within the mapping volume (page 33 lines 27-30); aligning a sensor (#100) at a first point (#210) within the mapping volume and measuring the magnetic field at the first point (#210) with the sensor (#100) to establish a first coordinate position (X_i, Y_i, Z_i) (page 35, lines 8-12); extrapolating the magnetic field of a next point (#220) ($X_i + dx, Y_i + dy, Z_i + dz$) along one coordinate axis by an added distance component (dx, dy, dz) (page 36 line 32 to page 37 line 4); calculating the coordinate position at the extrapolated

next point (#220) based on the extrapolated magnetic field to establish an extrapolated coordinate position (page 37, lines 6-9); determining the position difference between the extrapolated coordinate position and the actual coordinate position of the next point (#220) (page 37, lines 6-9); comparing the position difference to an error limit (page 37, lines 8-9); setting the added distance component (dx, dy, dz) according to a predetermined distance if the position difference is within the error limit, aligning the sensor (#100) at a new point (#230) within the mapping volume along another coordinate axis and measuring the magnetic field at the new point with the sensor to establish a new point (#230) coordinate position and repeating steps (d) – (g) along the other coordinate axis (page 37, lines 10-13); and setting the added distance component (dx, dy, dz) by decreasing the value of the added distance component if the position difference is not within the error limit and establishing an intermediate point (#220b) between the first point (#210) and the next point (#220) as the first position and repeating steps (d) – (g) along the same coordinate axis (page 37, lines 13-17).

REMARKS

Appellant submits this reply in response to the Notification of Non-Compliant Appeal Brief dated October 6, 2009. Appellant submits that the Appeal Brief complies with the requirements under 37 C.F.R. § 41.37(c)(1)(v). Specifically, the Appeal Brief has been amended to include the section entitled, Summary of Claimed Subject Matter.

Accordingly, in view of the foregoing, Appellant submits that the Appeal Brief is in compliance with 37 C.F.R. § 41.37(c)(1)(v).

Respectfully submitted,

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